

IN THE CLAIMS

Please amend the claims as follows:

1. (Original) An architecture for robot intelligence comprising:
a sensory database comprising at least one record, each record representing a direction from the robot and capable of storing a sensor signal;
a behavior database comprising a least one record, each record representing a behavior capable of being performed by the robot;
an attention agent for identifying a focus record in the sensory database; and
a behavior agent for selecting a behavior from the behavior database, the selection based, in part, on the focus record.
2. (Original) The architecture of claim 1 further comprising an sensory agent for storing the sensor signal into the sensory database record corresponding to the spatial direction of the sensor signal.
3. (Original) The architecture of claim 2 wherein the sensory agent stores a datum representing a time stamp associated with the sensory signal into the sensory database.
4. (Original) The architecture of claim 3 further comprising a coincidence agent for detecting temporal coincidence of a first sensor signal and a second sensor signal when the first sensor signal time stamp does not equal the second sensor time stamp.

Claims 5 – 19 (Cancelled)

20. (new) A method for providing short-term memory for an adaptive autonomous robot, the robot comprising at least one processor configured to execute at least one agent program, each of the at least one agent program configured to interact independently with other agent programs and at least one sensory processing unit associated with the at least one agent program, the method comprising:

creating a plurality of directions, each of the plurality of directions originating at the robot and having a set of nearest-neighbor directions defining a neighborhood associated with the each of the plurality of directions; and associating an event detected by the at least one sensory processing unit with one of the plurality of directions.

21. (new) The method of claim 5 further comprising fusing a first event associated with one of the plurality of directions with a second event associated with the same one of the plurality of directions.
22. (new) The method of claim 5 further comprising selecting the direction having the greatest number of events associated with that direction as a focus for the robot.
23. (new) The method of claim 5 wherein the number of the plurality of directions is fixed.
24. (new) The method of claim 8 wherein the number of the plurality of directions is selected such that an angle between one of the plurality of directions with one of its nearest-neighbor directions is less than 10°.
25. (new) The method of claim 5 wherein the plurality of directions are spaced such that each direction corresponds to a vertex of a geodesic sphere centered on the robot.
26. (new) The method of claim 5 further comprising re-associating an event previously associated with a previous direction with another one of the plurality of directions based on the movement of the robot.